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<u>L3</u>	(boundar\$3 same (orient\$6 or direction)) same (line or edge) same (four side or rectangle or rectangular\$5)	1142	<u>L3</u>
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<u>L9</u>	image with boundar\$3 with (orientation or direction)	1474	<u>L9</u>
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<u>L12</u>	(primary near2 angle) same (secondary near2 angle)	294	<u>L12</u>
<u>L13</u>	L12 same boundar\$3	3	<u>L13</u>

Page 2 of 2

<u>L17</u>

<u>L18</u>

39

21

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L16 same boundar\$3

L17 same (line or edge)

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L17

<u>L18</u>

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DOCUMENT-IDENTIFIER: US 6078700 A

TITLE: Method and apparatus for location and inspecting a two-dimensional image

including co-linear features

Brief Summary Text (12):

The grouping technique for searching for correspondence between model features and image features involves using a small, selected subset of image features. The image features selected for determining correspondence with model features are ones that are most likely to belong to a subset of a set of features comprising the model. For example, a vision system might be implemented in an application wherein it is desirable to find a particular rectangular object in the scene or image, e.g. a microchip. Although the captured image contains many objects, grouping could be applied by having the vision system select all groups of line segments from the \underline{image} , and more particularly all groups of \underline{line} segments that are at right angles to each other. The subsets or smaller groups of features, e.g. line segments at right angles to each other, would then be used to match to the chip \underline{model} , rather than using the entire set of line segments.